

AMENDMENTS TO THE SPECIFICATION:

On page 1 after the title, please insert the following:

RELATED APPLICATIONS

The present application is based on, and claims priority from International Application No. PCT/JP2004/16611 filed November 9, 2004, the disclosure of which is hereby incorporated by reference herein in its entirety.

On page 12, please amend paragraph 0036 as follows:

In this case, the sliding member should preferably be provided on a surface of the rotor that faces the stator. The sliding member should preferably be made of organic resin, such as Delrin (trademark) resin, acetal resin, fluororesin or the like, with a thickness in a range of 0.1mm to 1mm. Here, if the sliding member is over 1mm thick, there are cases where there is a loss in the produced torque, while if the sliding member is under 0.1mm thick, there are cases where the sliding characteristics and the durability of the sliding member fall.

In this case, it is preferable for the surface of an elastic body of the stator to be subjected to an ion plating process. This is because doing so improves the long-term reliability of the elastic body.

On page 43 to 44, please amend paragraph 0135 as follows:

In the haptic feedback controller 100 according to the first embodiment, silicon resin, rubber, or the like is stuck onto a bottom surface of the base ~~120-110~~ as a non-slip member.

On page 49 to 50, please amend paragraph 0153 as follows:

The haptic feedback controller 100a according to the second embodiment fundamentally has the same construction as the haptic feedback controller 100 according to the first embodiment, but the construction of the contact switches differs to that used in the haptic feedback controller 100 according to the first embodiment. That is, in the haptic feedback controller 100a according to the second embodiment, as shown in FIGS. 8(A) and 8(B), a switch member 112 is further provided on an inner circumferential part of a base 110a, and four contact switches 194a are disposed apart from one another in the circumferential direction on an inner

circumferential surface of the base 110a between the base 110a and the switch member 112 at the inner circumferential surface of the haptic feedback controller ~~110a~~100a. Four springs 196 are also disposed between the base 110a and the switch member 112.

On page 51, please amend paragraph 0156 as follows:

Also, for the haptic feedback controller 100a according to the ~~first~~second embodiment, by clicking an appropriate position of the switch member 112 on the inner circumferential surface of the haptic feedback controller 100a with his or her finger, the user can switch on one contact switch out of the four contact switches 194a. By doing so, predetermined control information can be outputted to the PC 10 that is the controlled appliance. It is also possible to select one out of a plurality of predetermined operation modes of the haptic feedback controller 100a.

On page 66, please amend paragraph 0199 as follows:

The haptic feedback controller 100m according to the fourteenth embodiment has fundamentally the same construction as the haptic feedback controller 100 according to the first embodiment, and therefore by using the haptic feedback controller ~~100~~100m according to the ~~first~~fourteenth embodiment as the knob that controls the feeding of the endoscope, it is possible to operate the controller more intuitively (for example, it is possible to produce feedback so that resistance is received in advance if the endoscope seems likely to strike the wall of an internal organ), which makes the endoscope easier to use.